ABSTRACT

First, an operator sequentially teaches the start point A, the
end point F and junction points B, C, D, E on the welding
path by moving the torch head by jog feed without paying
attention to the torch orientation. Next, a reference plane to
define the orientation of the torch is specified, and an
inclination angle and a forward angle representing the torch
orientation be inputted into a robot controller. On the basis
of these inputted angle data and the taught data, a basic
welding orientation is automatically calculated. Further
auxiliary points are set around the junction points B through
E each forming corner parts connecting straight lines; tool
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